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((ACLM/learn AND ACLM/"rotational speed") AND (SPEC/"ai" OR SPEC/neural?)) AND SPEC/shift?): 0 patents.

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Last logoff: 10oct06 14:46:27

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***** ANNOUNCEMENTS *****

NEW FILES RELEASED

***Verdict Market Research (File 769)

***EMCare (File 45)

***Trademarkscan - South Korea (File 655)

***Regulatory Affairs Journals (File 183)

***Index Chemicus (File 302)

***Inspec (File 202)

RESUMED UPDATING

***File 141, Reader's Guide Abstracts

RELOADS COMPLETED

***File 11, PsycInfo

***File 531, American Business Directory

*** The 2005 reload of the CLAIMS files (Files 340, 341, 942 is now available online.

DATABASES REMOVED

***File 196, FINDEX

***File 468, Public Opinion Online (POLL)

Information:

1. Announcements (new files, reloads, etc.)
2. Database, Rates, & Command Descriptions
3. Help in Choosing Databases for Your Topic
4. Customer Services (telephone assistance, training, sem
5. Product Descriptions

Connections:

6. DIALOG(R) Document Delivery
7. Data Star(R)

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\$0.00 0.334 DialUnits FileHomeBase
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File 6:NTIS 1964-2006/Oct W2
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<http://www.dialogclassic.com/264717RB.HTML?>

10/14/2006

T S2/3,KWIC/1

2/3,KWIC/1 (Item 1 from file: 95)

DIALOG(R)File 95:TEME-Technology & Management
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01289694 E99030200304

Influence of motion signals on the perceived position of sp
(Einfluss der Bewegungssignale auf die wahrgenommene Position
raeumlichen Musters)

Nishida, S; Johnston, A

NTT Kanagawa, J; Univ. College London, GB

Nature, v397, n6720, pp610-612, 1999

Document type: journal article Language: English

Record type: Abstract

ISSN: 0028-0836

1999

ABSTRACT:

...the motion aftereffect (MAE). It is thought that the MAE
accompanied by a shift in a spatial position of the pattern
providing psychophysical evidence for the dissociation of th
processing of motion and position that complements anatomica
physiological evidence of functional specialization in...

...is measured of a static windmill pattern after adaption t
and a gradual shift is found in orientation in the directi
illusory rotation, though at a rate much lower than the appa
speed. The orientation shift, which started to decline w
seconds, could persist longer than the MAE, and...

?

4/3,KWIC/1 (Item 1 from file: 8)

DIALOG(R)File 8:Ei Compendex(R)

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07537845 E.I. No: EIP05319278118

**Title: Autonomous mobile robot control algorithm based o
fuzzy behaviors in unknown environments**

Author: Li, Shou-Tao; Li, Yuan-Chun

Corporate Source: College of Communication Engineering Ji
Changchun 130022, ChinaSource: Jilin Daxue Xuebao (Gongxueban)/Journal of J
(Engineering and Technology Edition) v 35 n 4 July 2005. p 3

Publication Year: 2005

CODEN: JDXGAH ISSN: 1671-5497

Language: Chinese

...Abstract: achieved by fuzzy reasoning scheme, and high behaviors were composed of these primitive behaviors. Neur were used to select and fuse different behaviors like a per the motion speed and rotational velocity of the mobile change smoothly, because the sharp shift of different beh exacerbate the absolute position errors. The feasibility of design...

Descriptors: *Mobile robots; Algorithms; Fuzzy control; N
; Radio navigation

4/3,KWIC/2 (Item 2 from file: 8)

DIALOG(R)File 8:Ei Compendex(R)

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07097322 E.I. No: EIP04458446543

**Title: Neuro/fuzzy behavior-based control of a mobile ro
environments**

Author: Li, Shou-Tao; Li, Yuan-Chun

Corporate Source: Dept. of Contr. Sci. and Engineering Ji
ChangChun, 130025, ChinaConference Title: Proceedings of 2004 International Confer
Learning and Cybernetics

Conference Location: Shanghai, China Conference Date: 20

E.I. Conference No.: 63733

Source: Proceedings of 2004 International Conference on M

and Cybernetics Proceedings of 2004 International Confer
Learning and Cybernetics v 2 2004. (IEEE cat n 04EX826)

Publication Year: 2004

ISBN: 0780384032

Language: English

...Abstract: discussed in our case. These elementary behav
achieved by means of fuzzy reasoning scheme. Neural netwo
select different behaviors so that the motion speed and
velocity of the mobile robot are changed smoothly. The sharp
difference behaviors will exacerbate the absolute position e
explanation of the algorithm is...

Descriptors: *Mobile robots; Fuzzy control; Neural netwo
; Decision making; Problem solving; Genetic algorithms; Math
; Computer simulation